AMENDMENTS TO THE CLAIMS

1-12. (Canceled)

13. (Original) A method comprising:

outputting a maximum peak force from an actuator on a manipulandum, the maximum peak force associated with a maximum power that the actuator can utilize instantaneously; and

reducing the output of the maximum peak force to a n output of a nominal peak force from the actuator when the power utilized by the actuator exceeds an average power level over a predetermined period of time, the nominal peak force associated with a maximum power that the actuator can utilize in continuous steady-state operation.

14. (Currently Amended) The method of claim 13, wherein outputting the maximum peak force occurs upon initial contact with a simulated object.

15. (Currently Amended) The method of claim 13, wherein the maximum peak force comprises a magnitude of about twice the magnitude of the nominal peak force.

16. (Currently Amended) The method of claim 13, wherein the nominal peak force is associated with an average current during operation of the actuator.

17. (Currently Amended) The method of claim 13, determining when the power utilized by the actuator exceeds the average power level over the predetermined period of time.

18. (Currently Amended) The method of claim 13, wherein the predetermined period of time is about two seconds.

19. (Canceled)

20. (Currently Amended) A The method of claim 19, further comprising:
receiving an input signal comprising a position of a manipulandum;

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<u>determining a stored force feedback effect to contribute to a force output by an actuator</u>

<u>on the manipulandum, the stored force feedback effect comprising a force feedback effect type</u>

<u>and a magnitude;</u>

receiving a second signal comprising a calculated force feedback effect; <u>and</u>

determining a combined force feedback effect to contribute to a force output by an

actuator on the manipulandum, the combined force feedback effect comprising the stored force

feedback effect and the calculated force feedback effect.

21.   (New) The method of claim 20, wherein the manipulandum comprises a joystick.

22.   (New) The method of claim 20, wherein the stored force feedback effect comprises one

of a detent effect, a wall effect, and a spring effect.

23.   (New) The method of claim 20, wherein the stored force feedback effect includes at least

one parameter, and wherein the at least one parameter is at least one of a stiffness parameter, a

damping parameter, a force parameter, and a distance parameter.

24   (New) The method of claim 20, wherein the combined force feedback effect comprises a

sum of force contributions from a plurality of stored force feedback effects.

25.   (New) The method of claim 20, further comprising:

calculating a velocity of a movement of the manipulandum based at least in part on

information received from a position sensor coupled to the manipulandum, and

wherein the force output by the actuator is based at least in part on a velocity of a

movement of the manipulandum.